LISTING OF THE CLAIMS

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

What is claimed is:

1. (Original) A robot, comprising:

a mobile holonomic platform;

a camera coupled to said mobile holonomic platform;

an arm coupled to said mobile holonomic platform; and,

a first grasper coupled to said arm.

2. (Original) The robot of claim 1, further comprising a monitor coupled to said mobile holonomic platform.

3. (Original) The robot of claim 1, wherein further comprising a shoulder actuator coupled to said arm.

4. (Original) The robot of claim 1, wherein said arm has an elbow actuator.

5. (Original) The robot of claim 1, wherein said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm having an actuator that moves

said second linkage relative to said first linkage in a first degree a freedom in a first mode, and in a second degree of freedom in a second mode.

6. (Original) The robot of claim 1, wherein said first grasper is coupled to a wrist joint of said arm.

7. (Original) The robot of claim 1, further comprising a second grasper coupled to said arm.

8. (Original) The robot of claim 5, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

9. (Original) A robot, comprising:

a mobile holonomic platform;

a camera coupled to said mobile holonomic platform;

an arm coupled to said mobile holonomic platform; and,

first grasper means for grasping an object.

10. (Original) The robot of claim 9, further comprising a monitor coupled to said mobile holonomic platform.

11. (Original) The robot of claim 9, wherein further comprising a shoulder actuator coupled to said arm.

12. (Original) The robot of claim 9, wherein said arm has an elbow actuator.

13. (Original) The robot of claim 9, wherein said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm having actuator means for moving said second linkage relative to said first linkage in a first degree a freedom in a first mode, and in a second degree of freedom in a second mode.

14. (Original) The robot of claim 9, wherein said first grasper means is coupled to a wrist joint of said arm.

15. (Original) The robot of claim 9, further comprising second grasper means for grasping the object.

16. (Original) The robot of claim 13, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

17. (Original) A method for operating a robot, comprising:

moving a mobile holonomic platform that is coupled to an arm;

moving an arm coupled to the mobile holonomic platform; and,

actuating a first grasper to grasp an object.

18. (Original) The method of claim 17, further comprising grasping and moving a wheelchair.

19. (Original) The method of claim 17, further comprising capturing an image in a camera that is coupled to the mobile holonomic platform.

20. (Original) The method of claim 17, further comprising displaying an image on a monitor coupled to the mobile holonomic platform.

21. (Original) A robot system, comprising:

a broadband network;

a remote station coupled to said broadband network, said remote station having a handle that can be manipulated to generate movement signals that are transmitted through said broadband network;

a robot that is coupled to said broadband network and receives said movement signals from said handle of said remote station, said robot including;

a mobile holonomic platform;

a camera coupled to said mobile holonomic platform;

an arm coupled to said mobile holonomic platform; and,

a first grasper coupled to said arm.

22. (Original) The robot system of claim 21, further comprising a monitor coupled to said mobile holonomic platform.

23. (Original) The robot system of claim 21, wherein further comprising a shoulder actuator coupled to said arm.

24. (Original) The robot system of claim 21, wherein said arm has an elbow actuator.

25. (Original) The robot system of claim 21, wherein, said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm further having an actuator that moves said second linkage relative to said first linkage in a first degree a freedom in a first mode, and in a second degree of freedom in a second mode in response to said movement signals.

26. (Original) The robot system of claim 21, wherein said first grasper is coupled to a wrist joint of said arm.

27. (Original) The robot system of claim 21, further comprising a second grasper coupled to said arm.

28. (Original) The robot system of claim 25, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

29. (Original) A robot system, comprising:

a broadband network;

input means for generating movement signals and transmitting said movement signals through said broadband network;

a robot that is coupled to said broadband network and receives said movement signals of said input means, said robot including;

a mobile holonomic platform;

a camera coupled to said mobile holonomic platform;

an arm coupled to said mobile holonomic platform; and,

first grasper means for grasping an object.

30. (Original) The robot system of claim 29, further comprising a monitor coupled to said mobile holonomic platform.

31. (Original) The robot system of claim 29, wherein further comprising a shoulder actuator coupled to said arm.

32. (Original) The robot system of claim 29, wherein said arm has an elbow actuator.

33. (Original) The robot system of claim 29, wherein, said arm includes a first linkage, and a second linkage coupled to said first linkage, said arm further having actuator means for moving said second linkage relative to said first linkage in a first degree a freedom in a first mode, and a second degree of freedom in a second mode in response to said movement signals.

34. (Original) The robot system of claim 29, wherein said first grasper means is coupled to a wrist joint of said arm.

35. (Original) The robot system of claim 29, further comprising second grasper means for grasping the object.

36. (Original) The robot system of claim 33, wherein said first degree of freedom pivots about an elbow axis and said second degree of freedom slides relative to the elbow axis.

37. (Original) A method for operating a robot, comprising:

generating a platform movement command;

transmitting the platform movement command through a broadband network;

moving a mobile holonomic platform that is coupled to an arm in response to the transmitted movement command;

generating a first arm movement command;

transmitting the first arm movement command through the broadband network;

moving the arm in response to the first arm movement command;

generating a first grasper command;

transmitting the first grasper command through the broadband network; and,

actuating a first grasper in accordance with the first grasper command.

38. (Original) The method of claim 37, further comprising grasping and moving a wheelchair.

39. (Original) The method of claim 37, further comprising capturing an image in a camera that is coupled to the mobile holonomic platform.

40. (Original) The method of claim 37, further comprising displaying an image on a monitor coupled to the mobile holonomic platform.